

ABSTRACT

A robot arm is provided with an end effector for grasping an object and a force sensor for detecting a force acted upon the end effector. In the state in which end effector grasps an object, when there is a change in the force acting on the end effector detected by the force sensor, outputted is a signal for releasing the force of the end effector grasping the object. The object grasped by the end effector can be taken out as if the object were handed from person over to person.